Abstract

A method and a computer program for generating a model for the functional response of a control device (120), for generating a manipulated variable (u_d) for a controlled system (130) in response to a preselected setpoint value (y_d) is described. The model is also generated for nonlinear controlled systems (130) by performing the following steps: calculating the Nth derivative of the controlled variable as a function of the manipulated variable and of the controlled variable (y) itself and/or its derivatives of the nth order with respect to time and generating the model for the control device (120) by solving the Nth derivative of the controlled variable (y) for the manipulated variable (u_d). Figure 1.

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